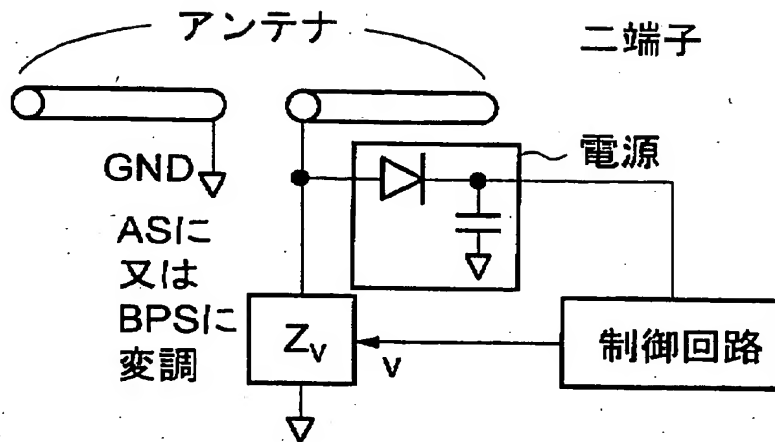
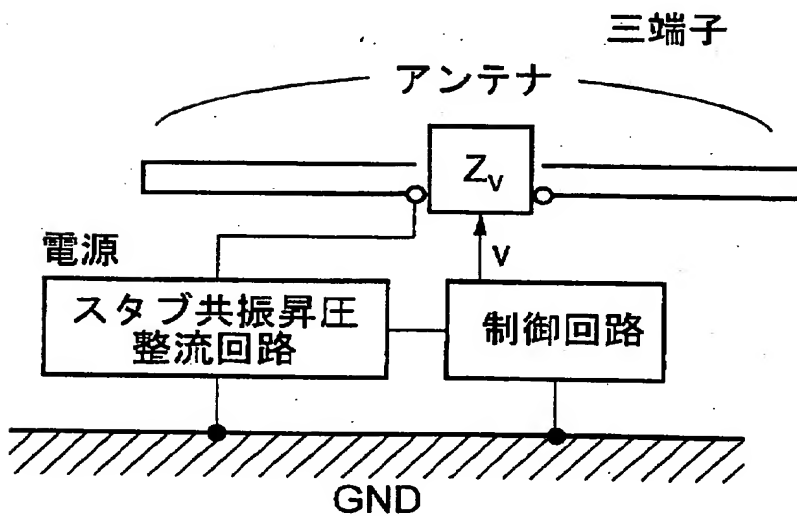


[図1]



従来

[図2]



本発明

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絶縁体

基板

チップ

制御回路

ストリップ導体

地板導体

点Cはアンテナの給電点

点Fはスルーホールで地板へ接続

5

30

25

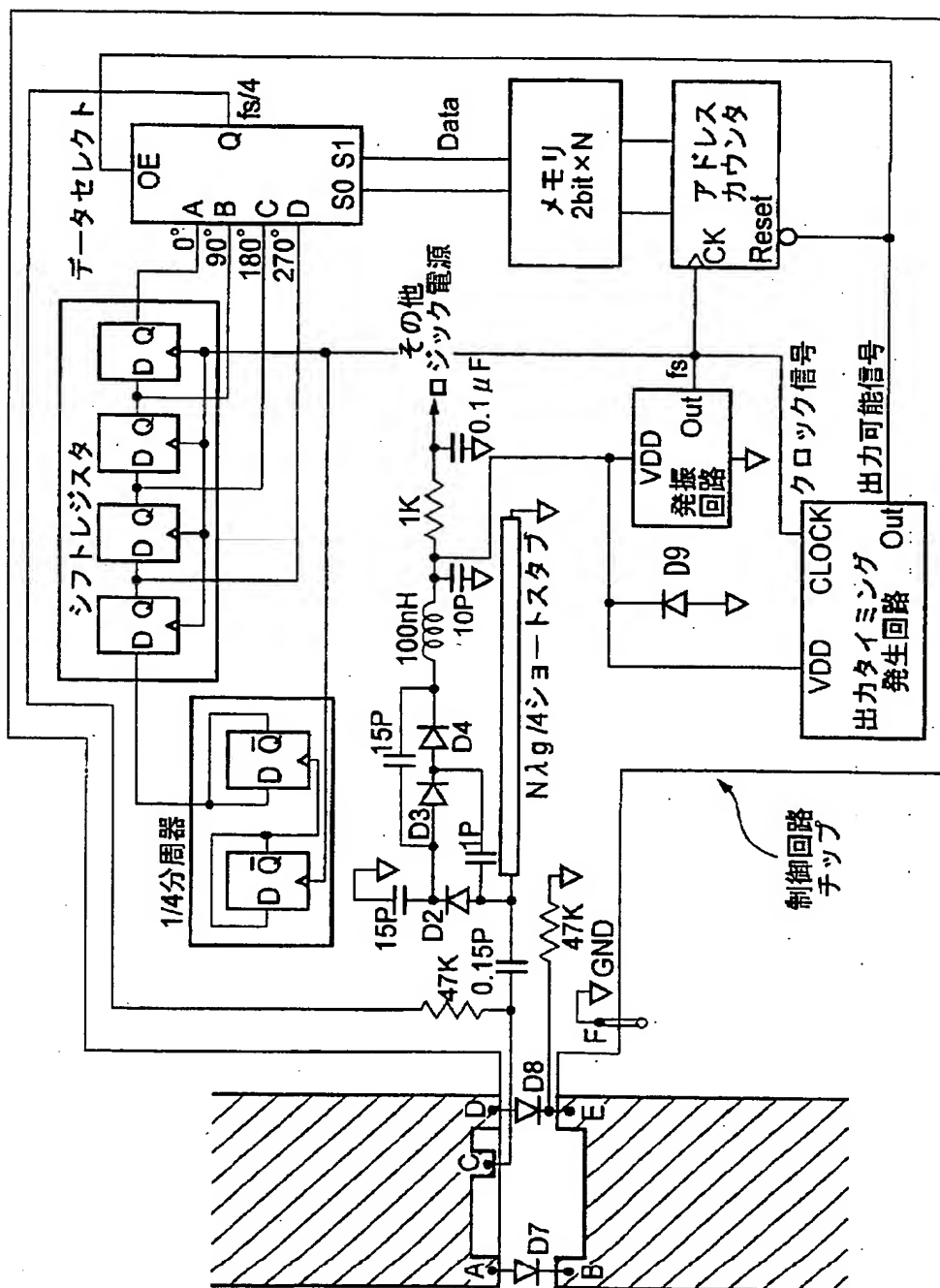
60

20

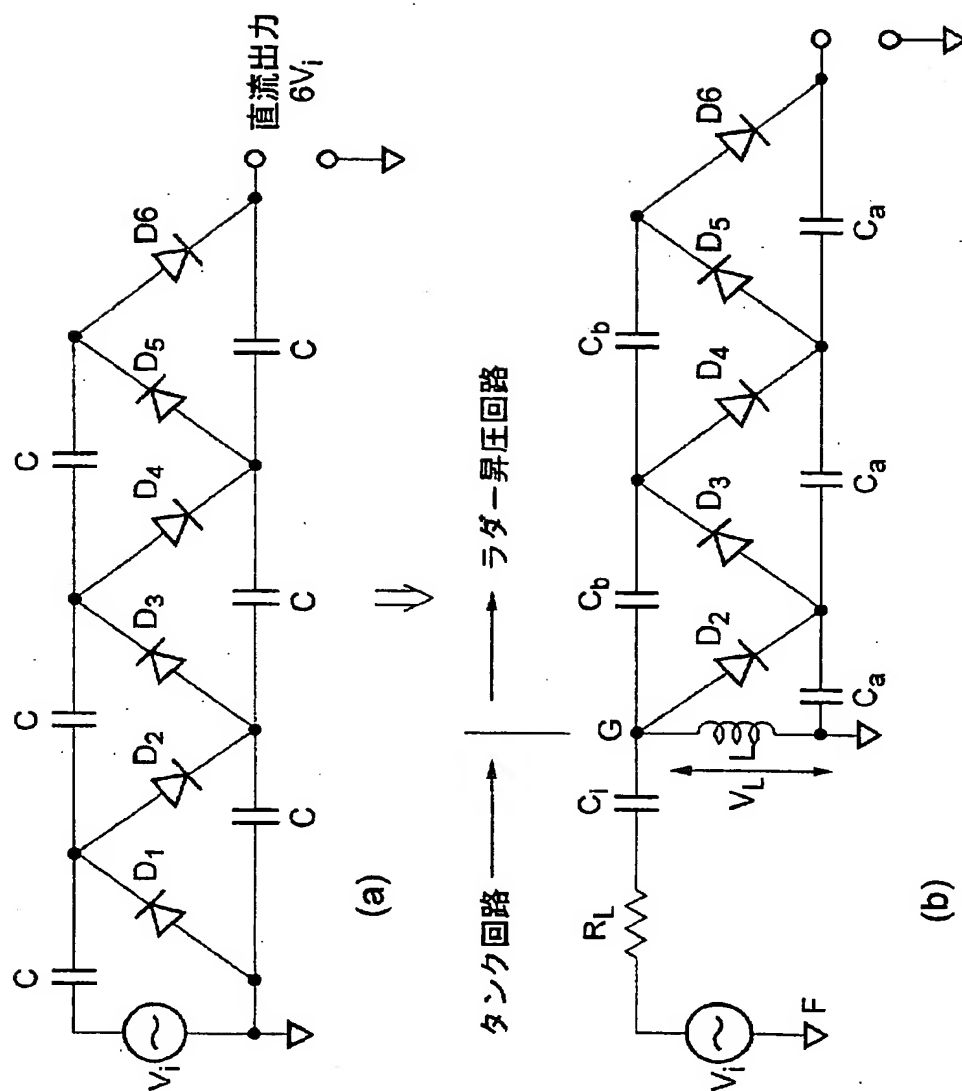
厚さ1

サイズ(mm)

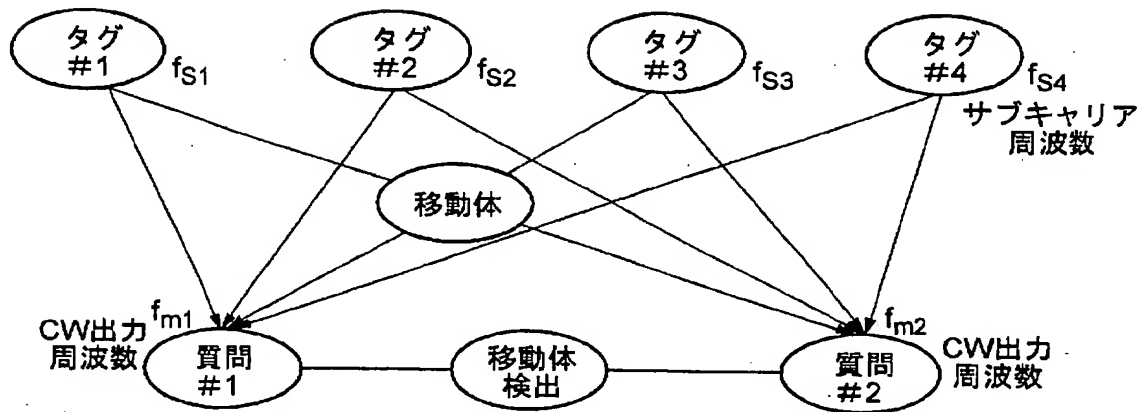
[図4]



[図5]



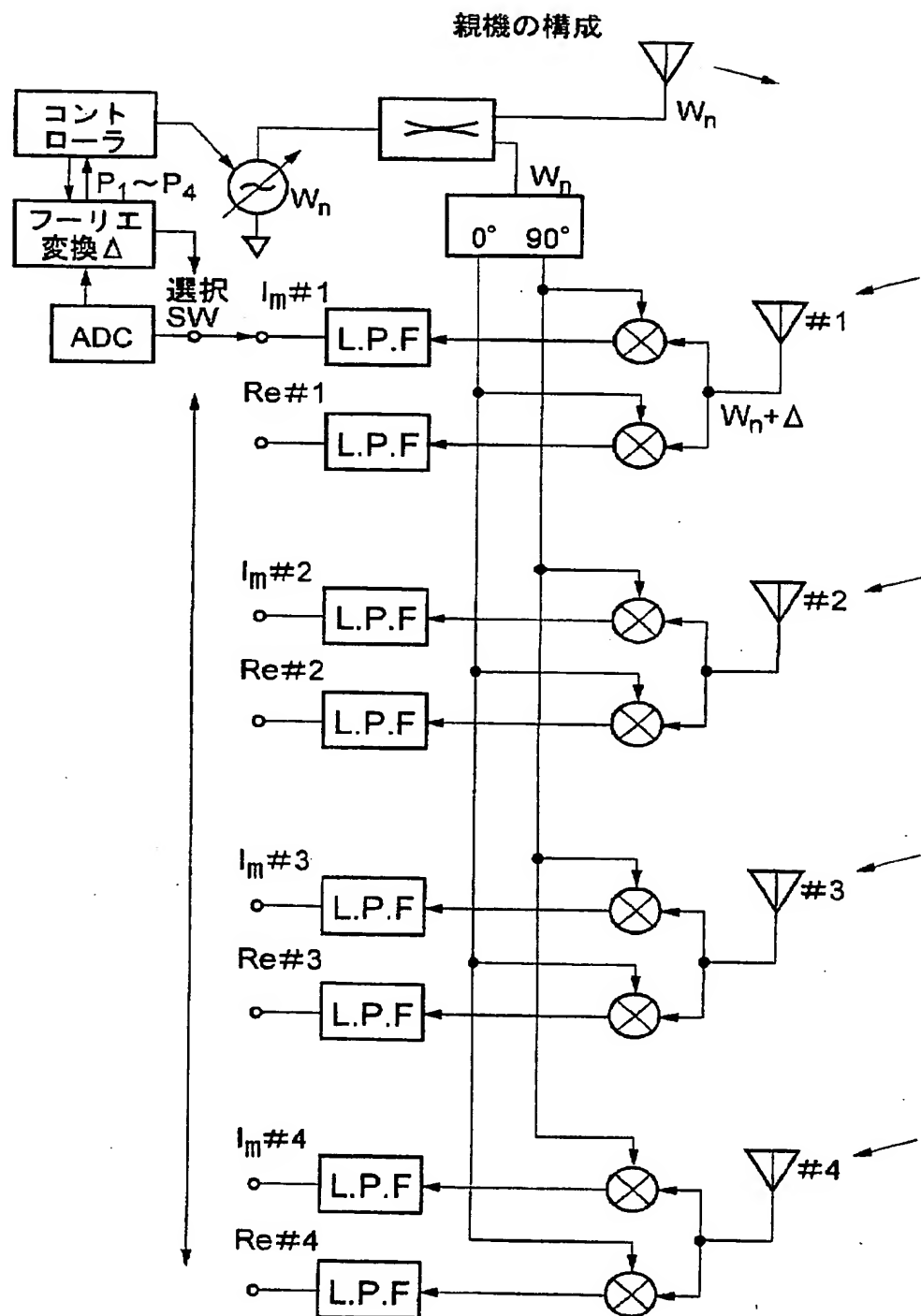
[図6]



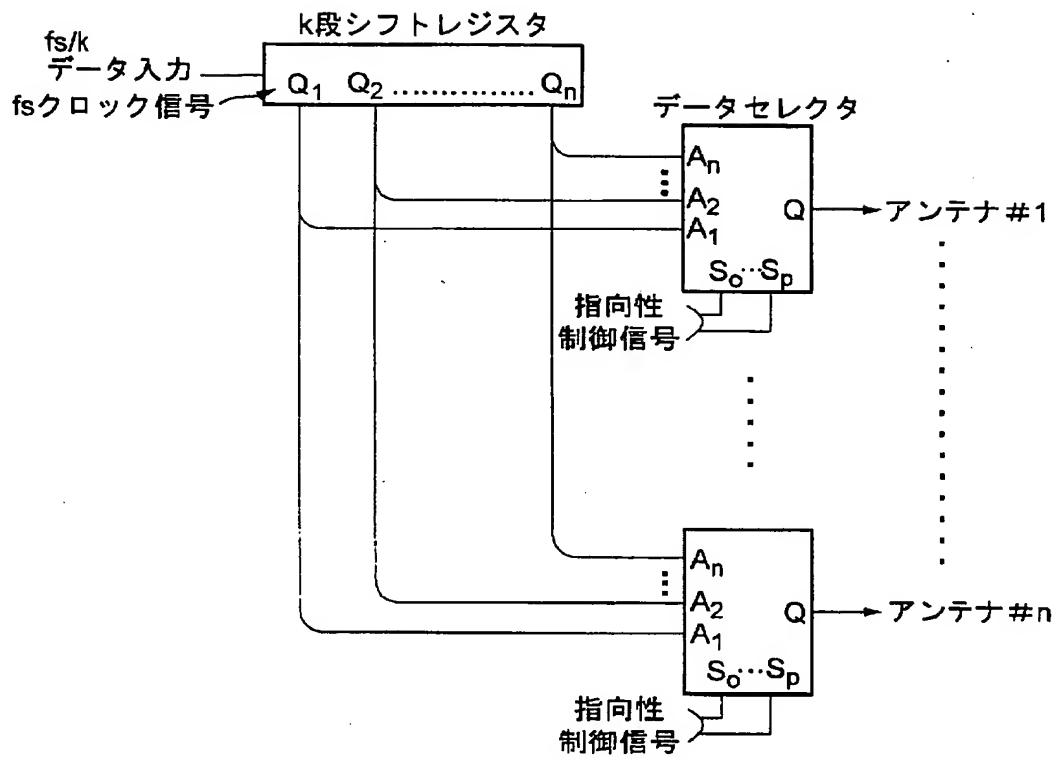
タグ応答信号の有無

		タグ番号			
		#1	#2	#3	#4
質問番号	#1	○	○	×	○
	#2	×	○	○	○

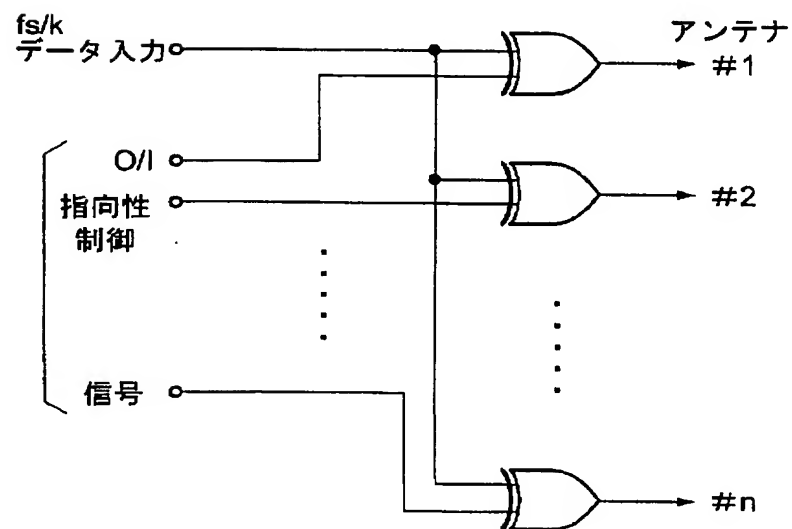
[図7]



[図8]

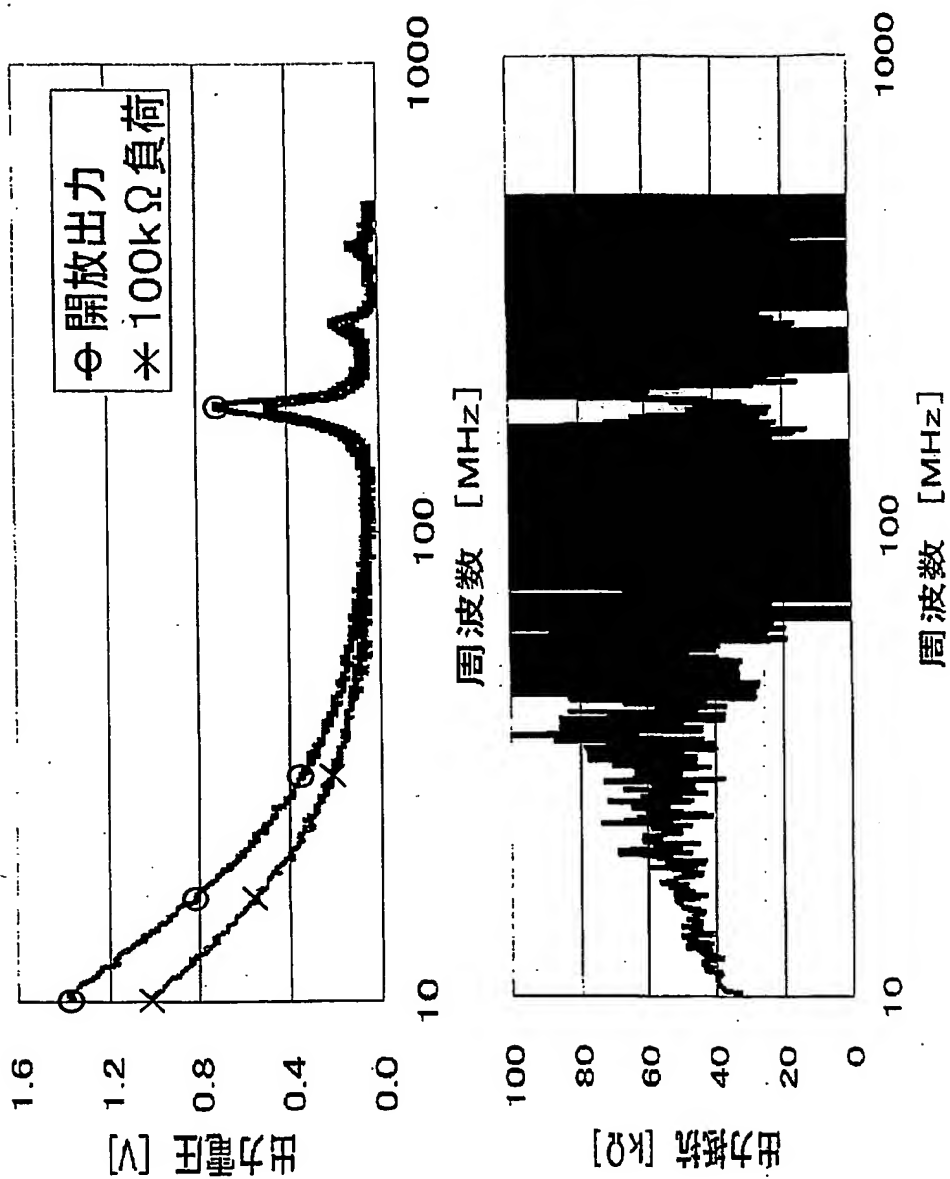


[図9]



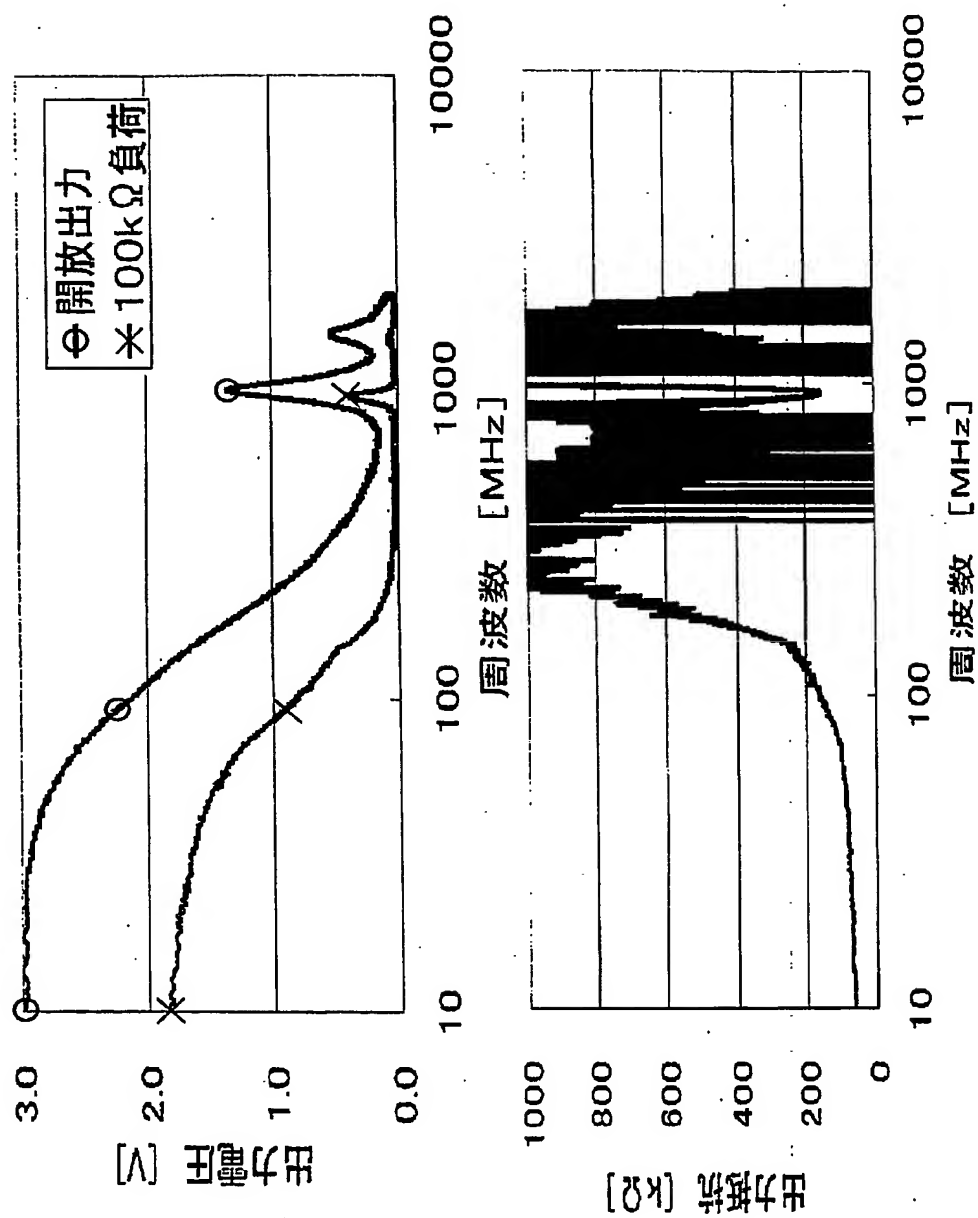
8/30

【図10】



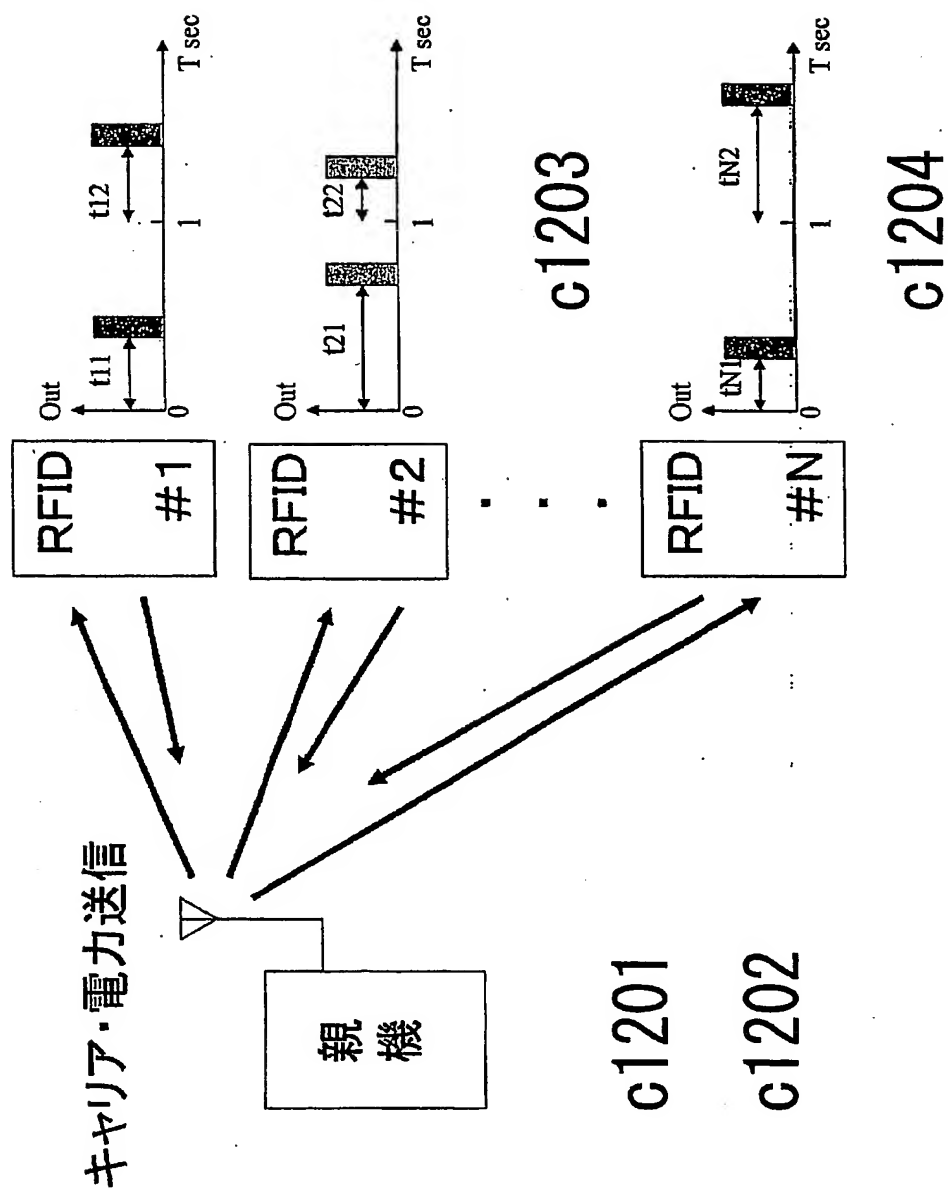
9/30

【図 11】



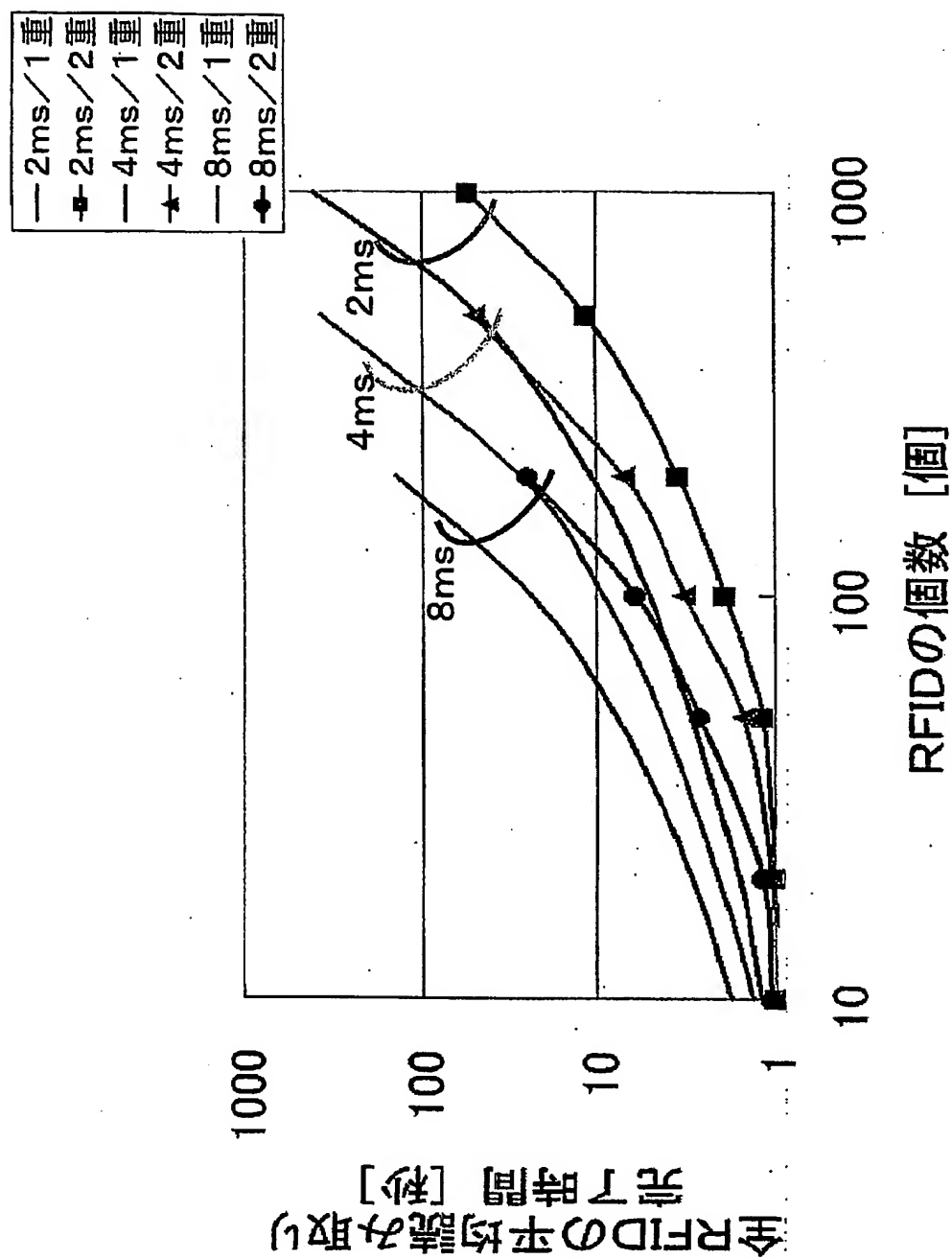
10/30

【図 1 2】



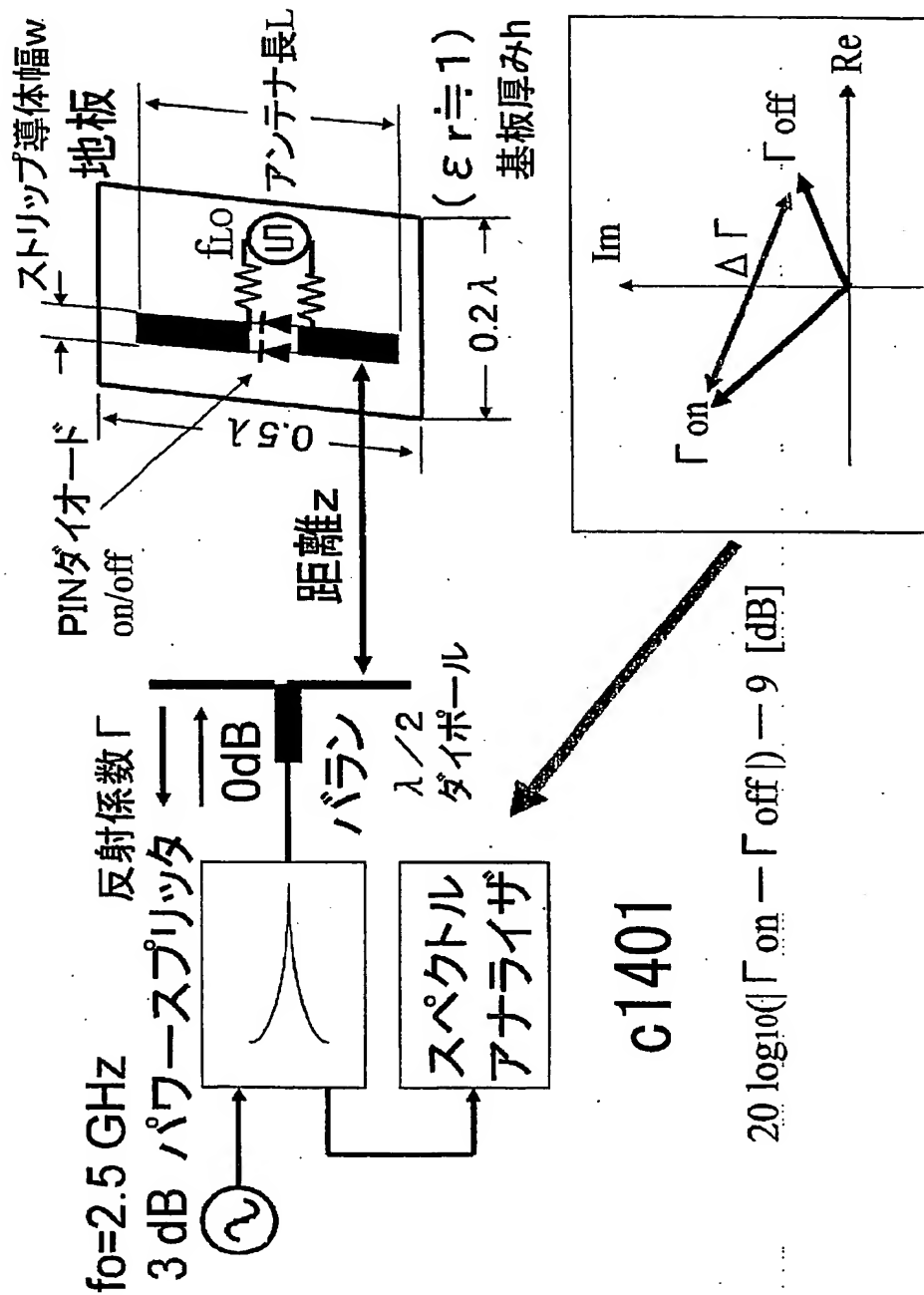
11/30

【図 13】

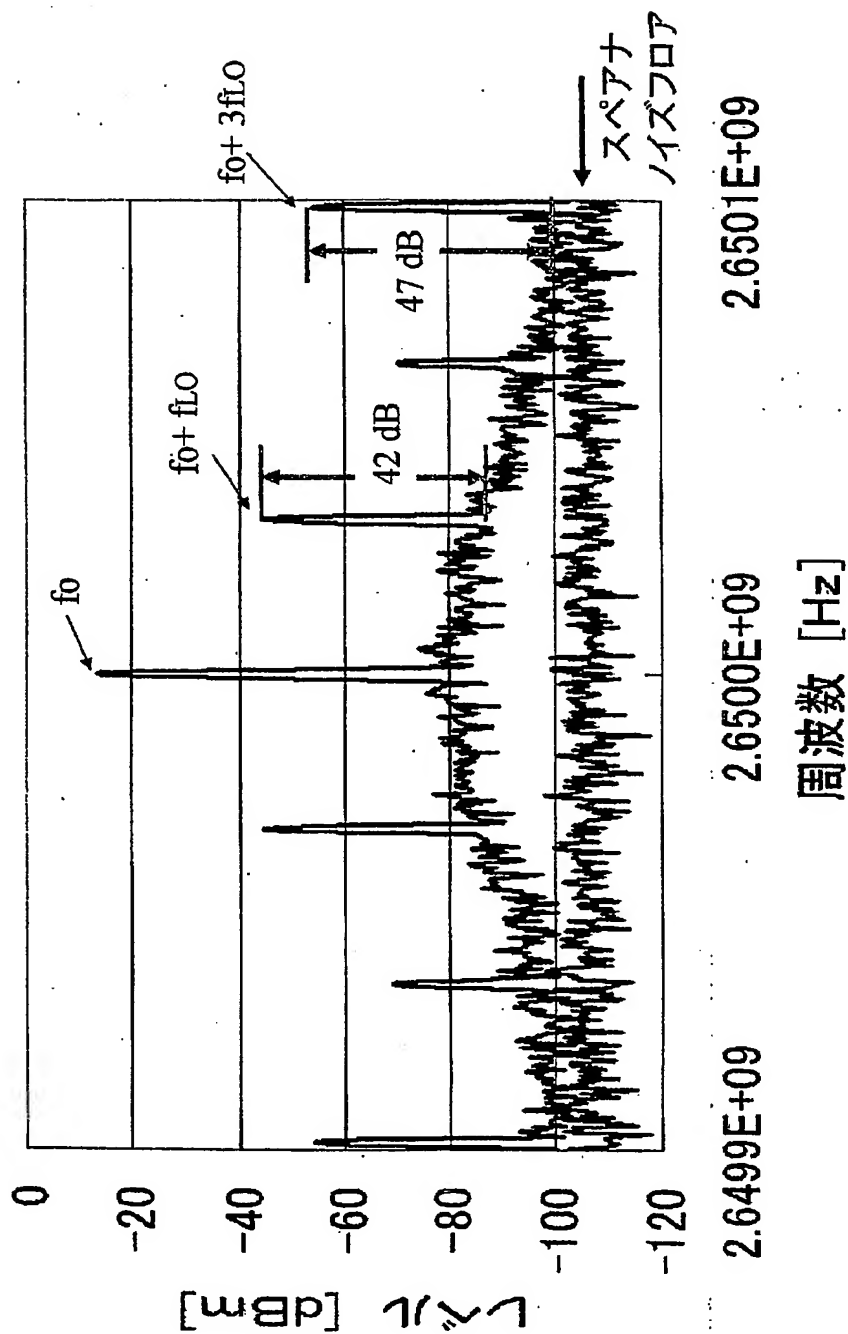


12/30

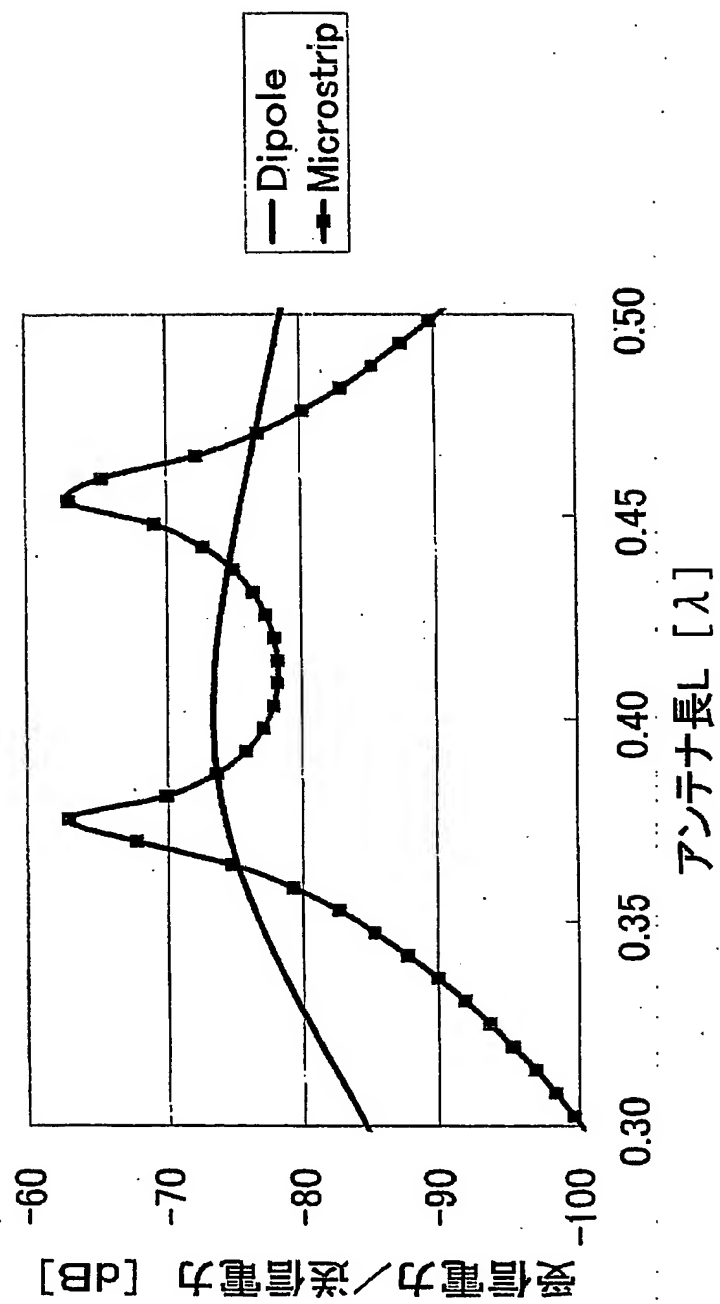
【図14】



【図15】

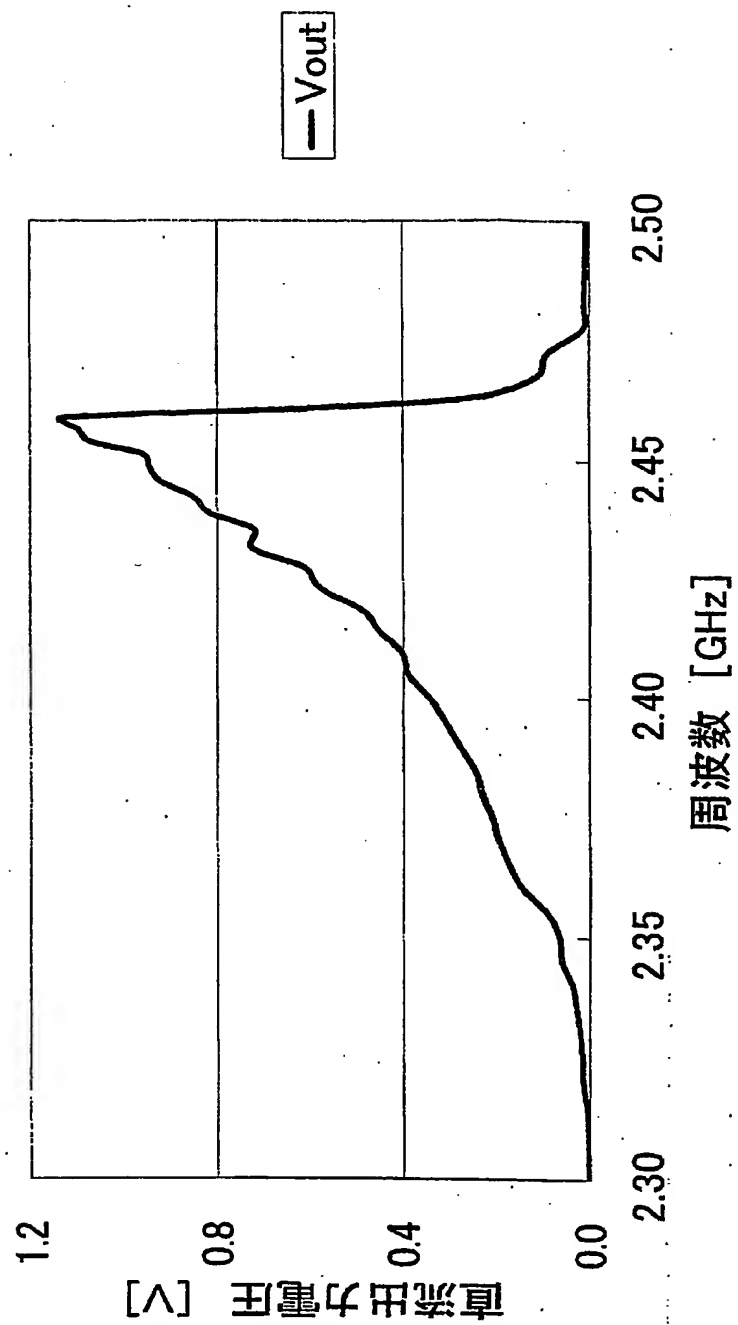


【図16】

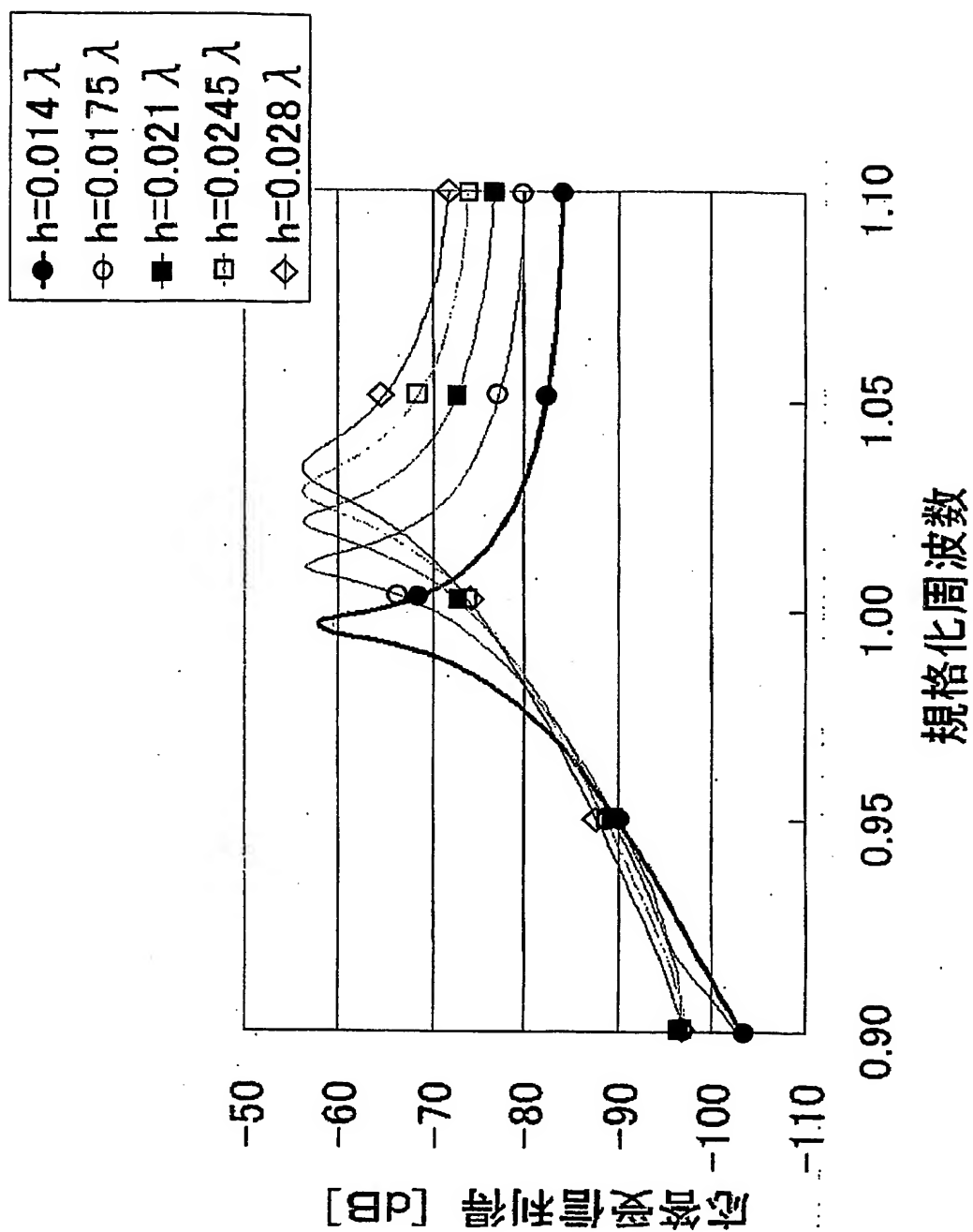


15/30

【図 17】

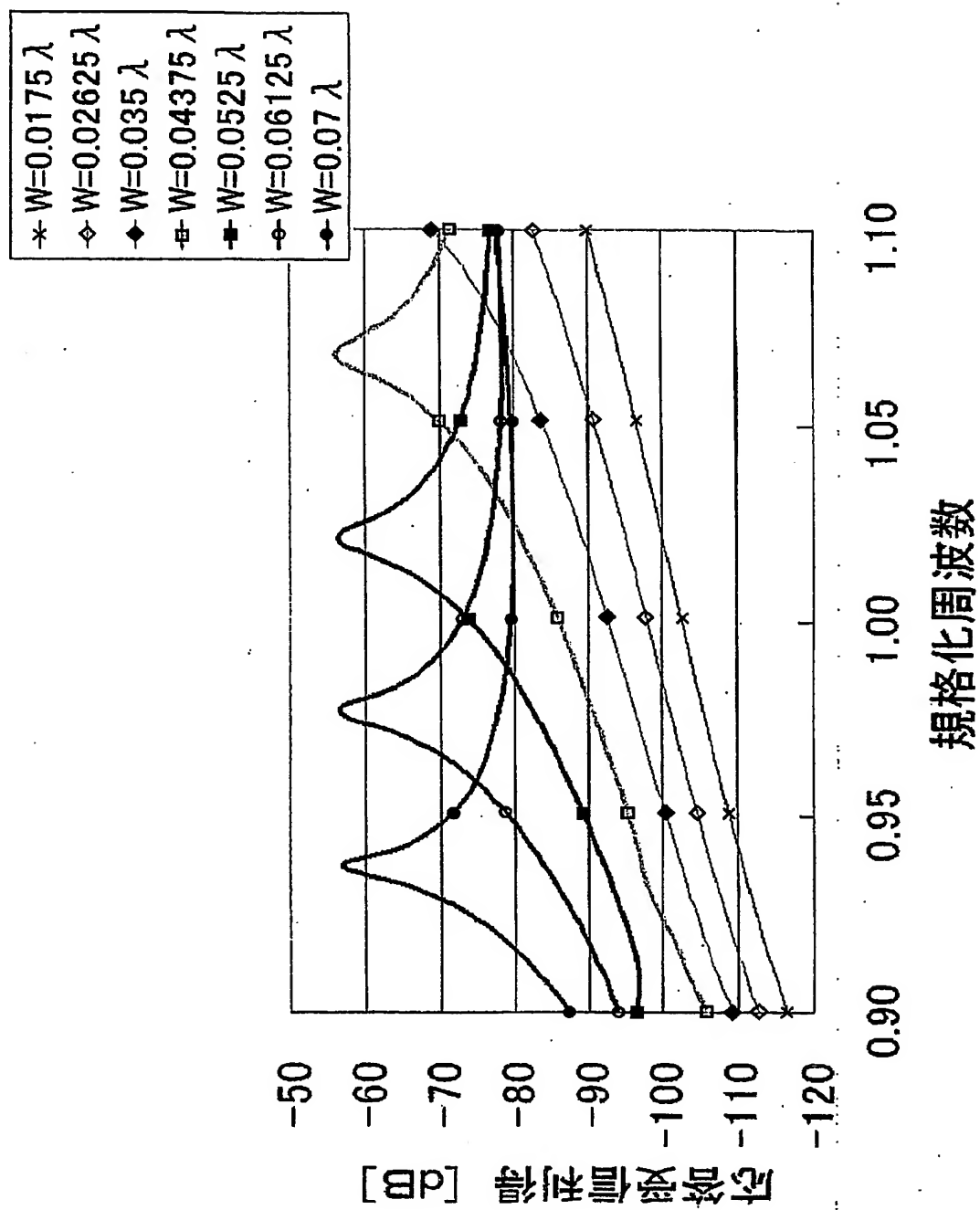


【図18】

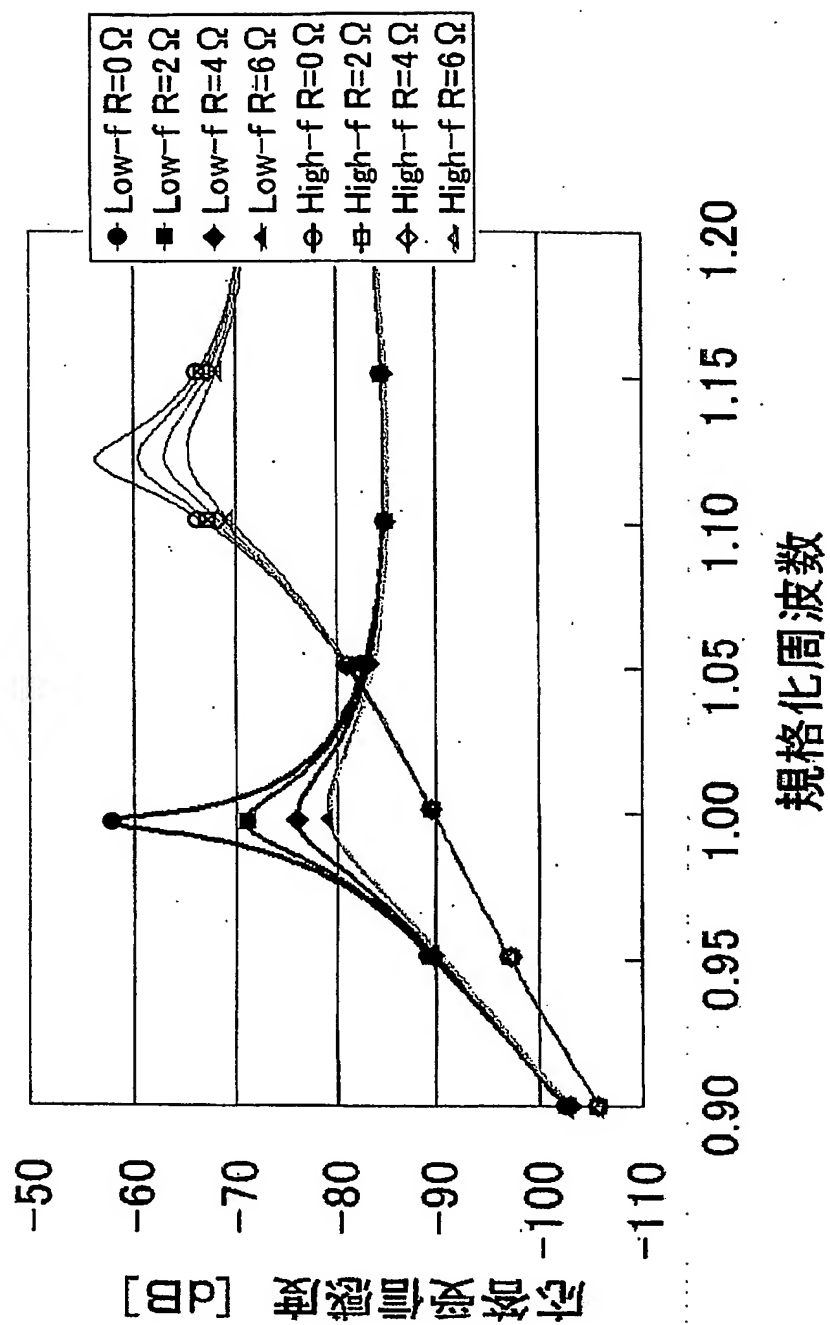


17/30

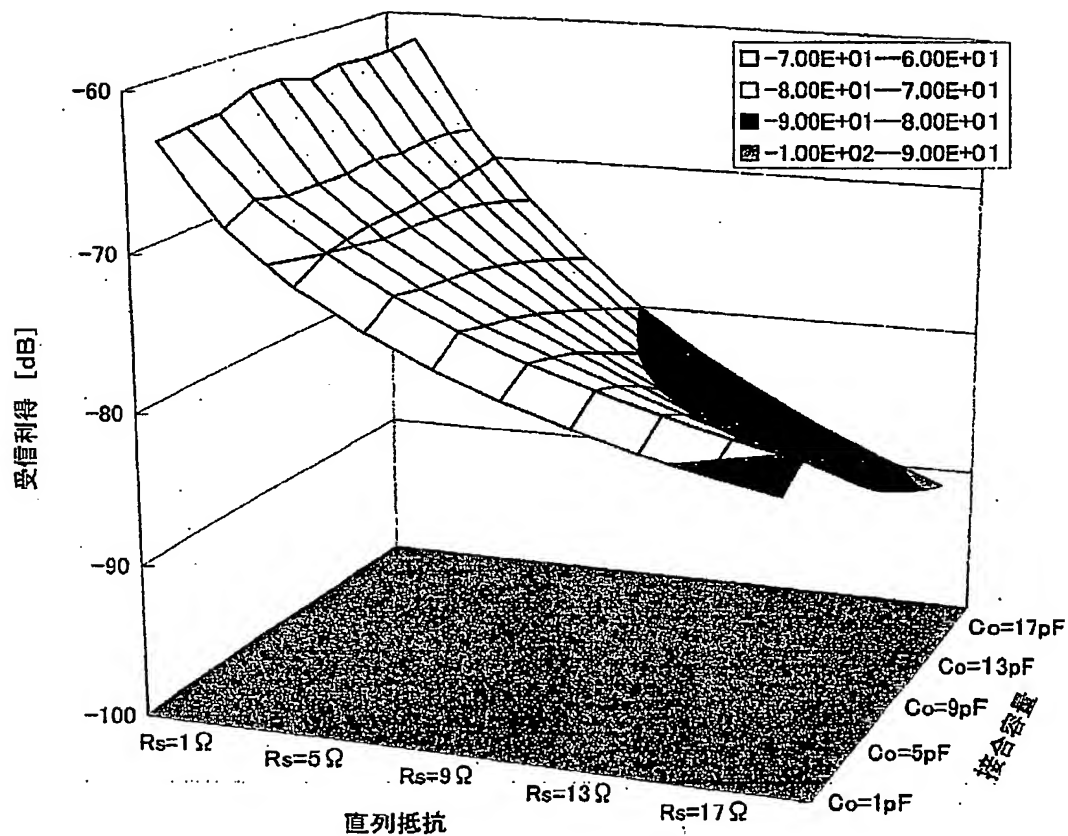
【図19】



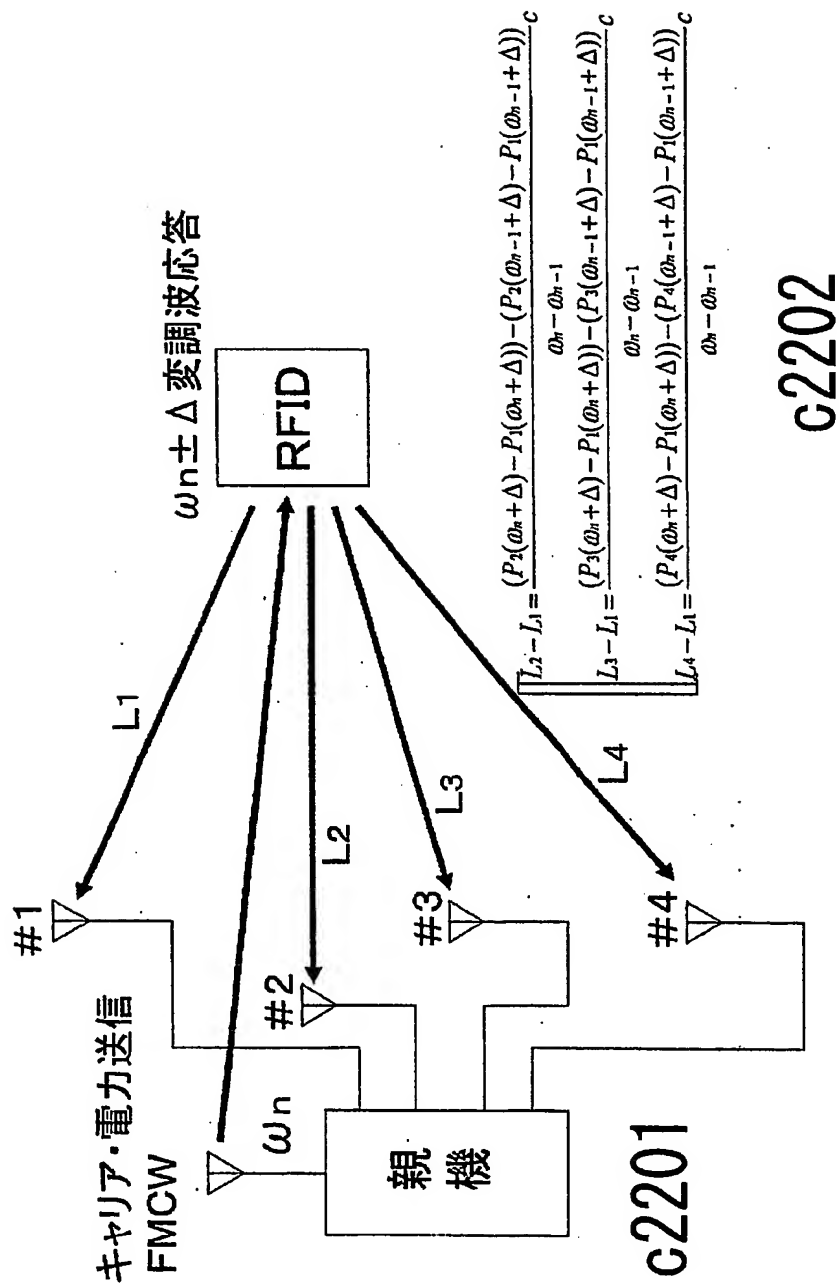
【図 20】



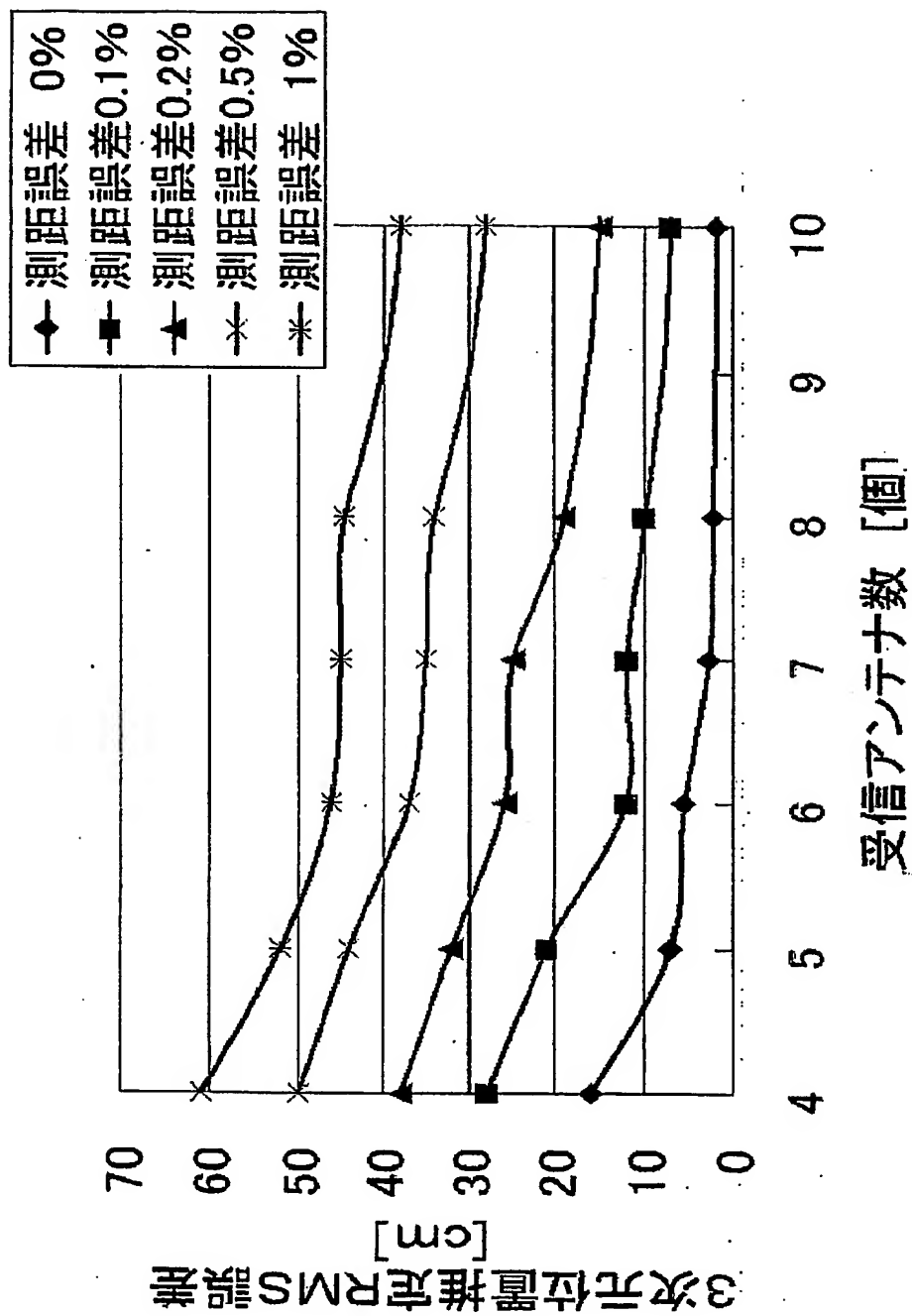
【図 21】



【図 22】

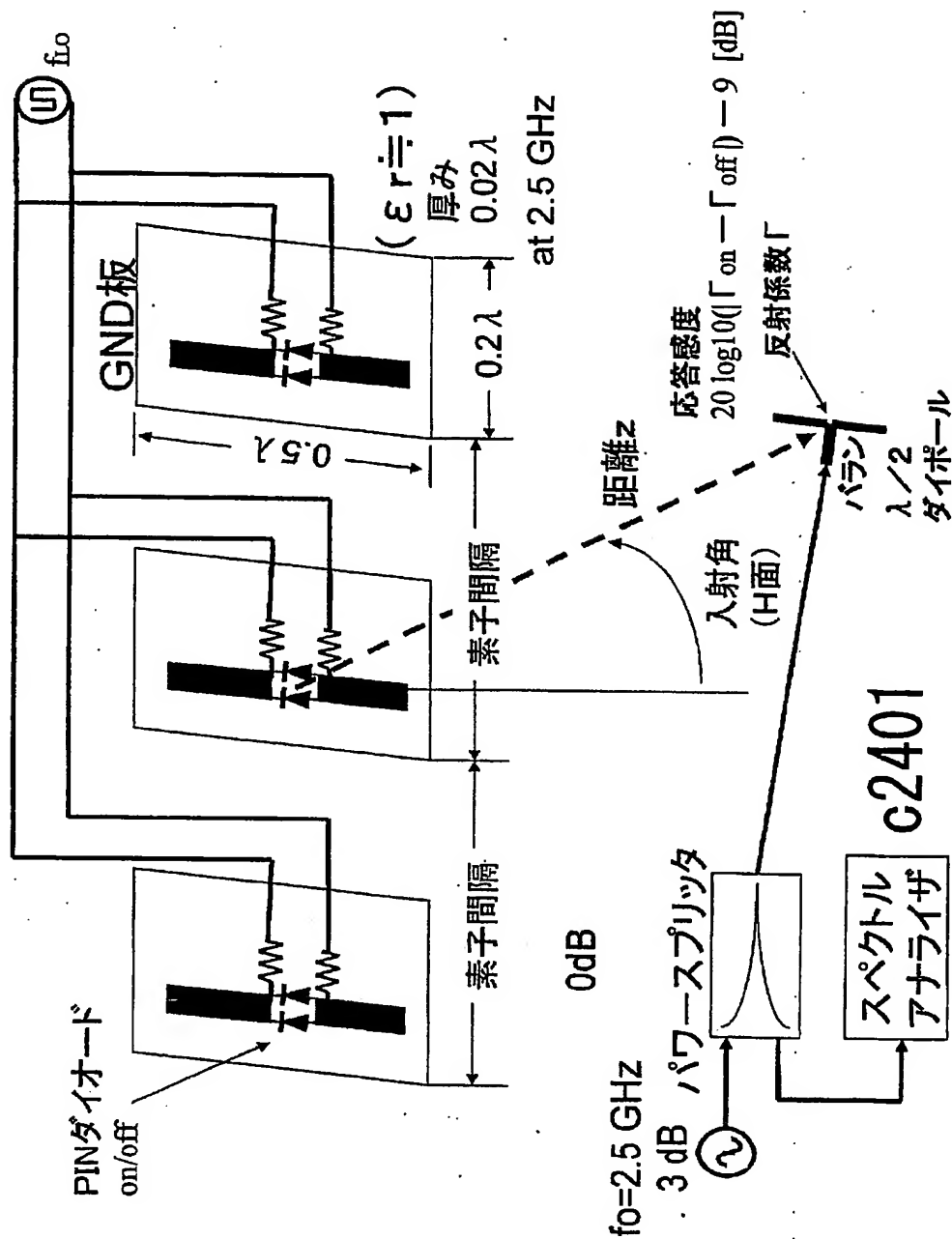


【図 23】

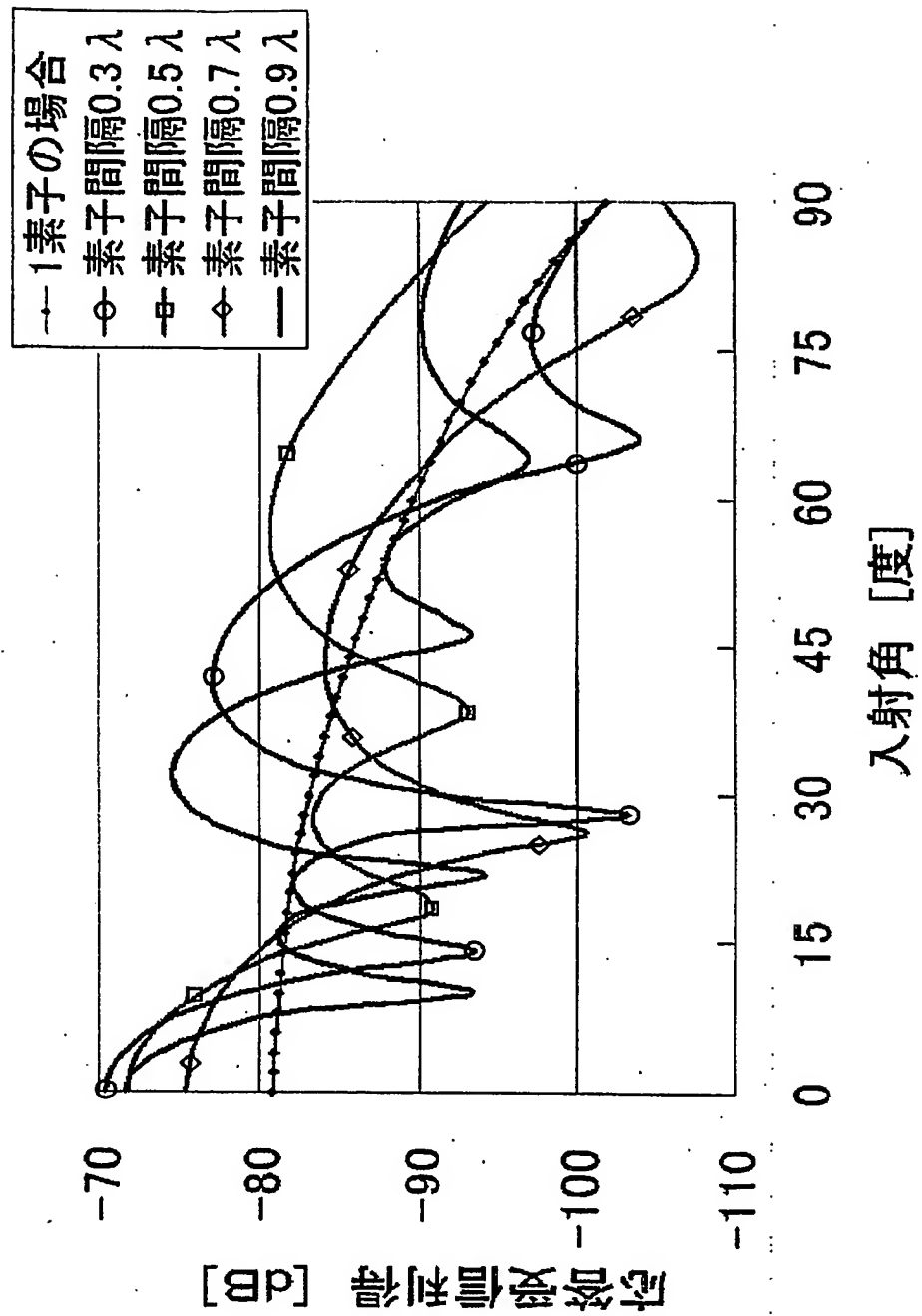


22/30

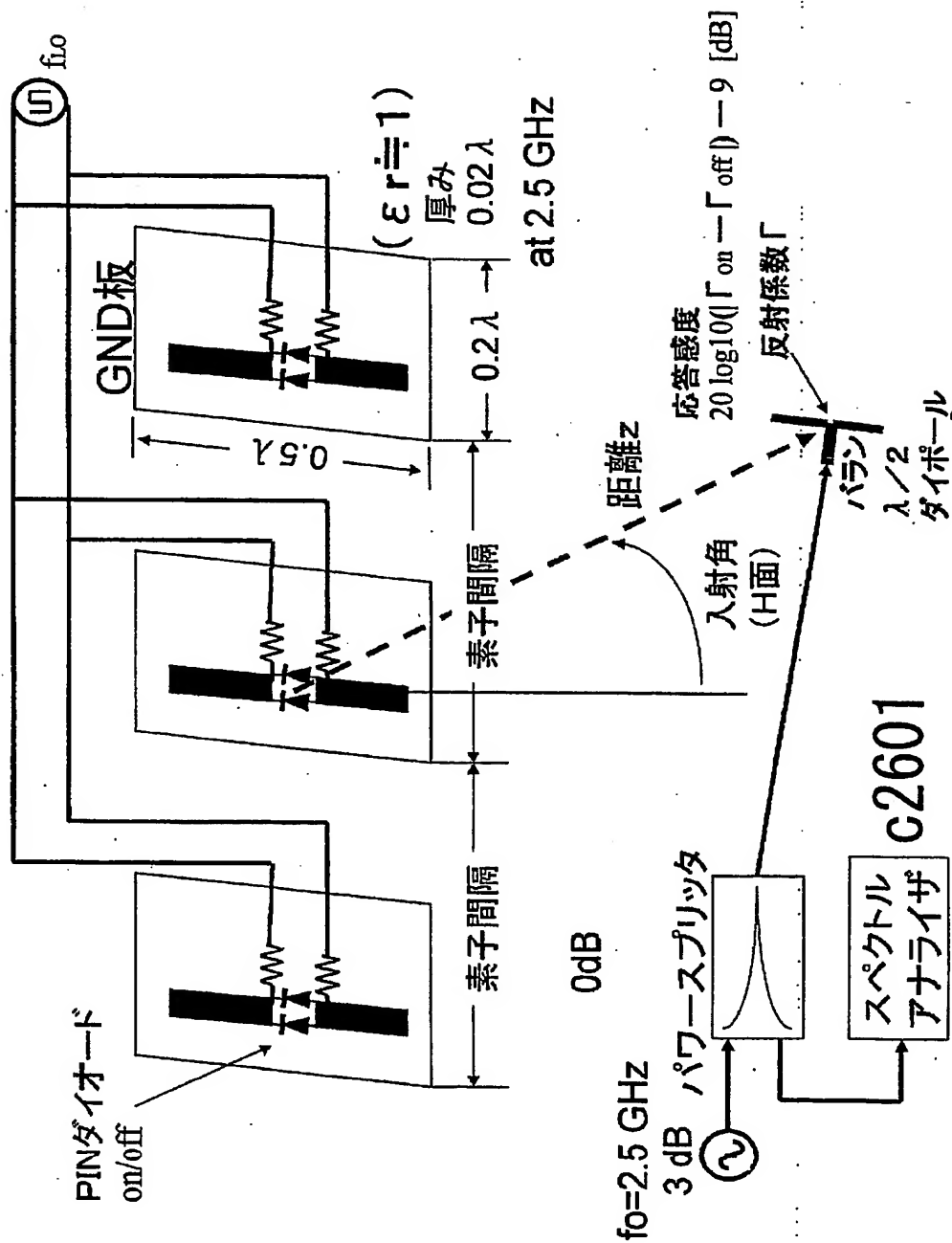
【図 24】



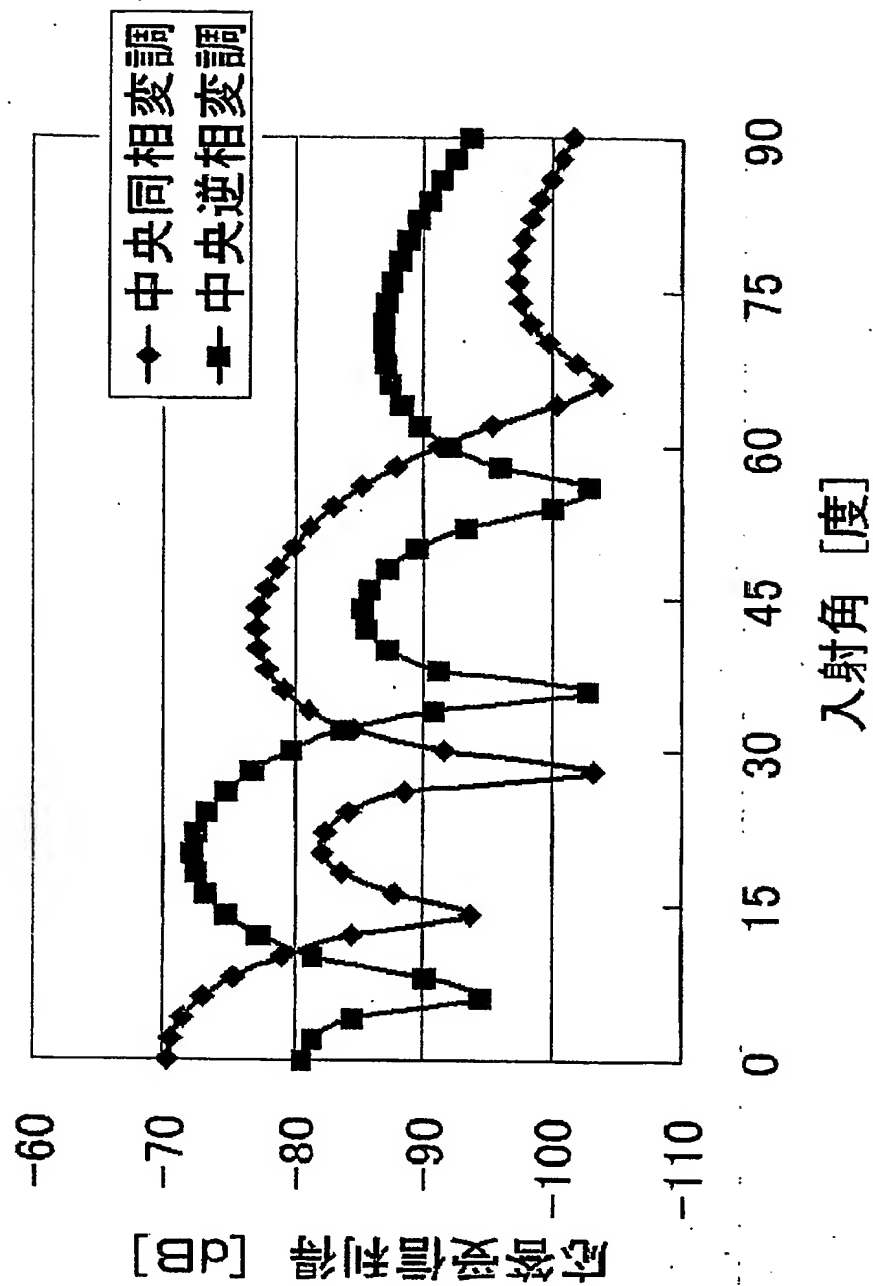
【図 25】



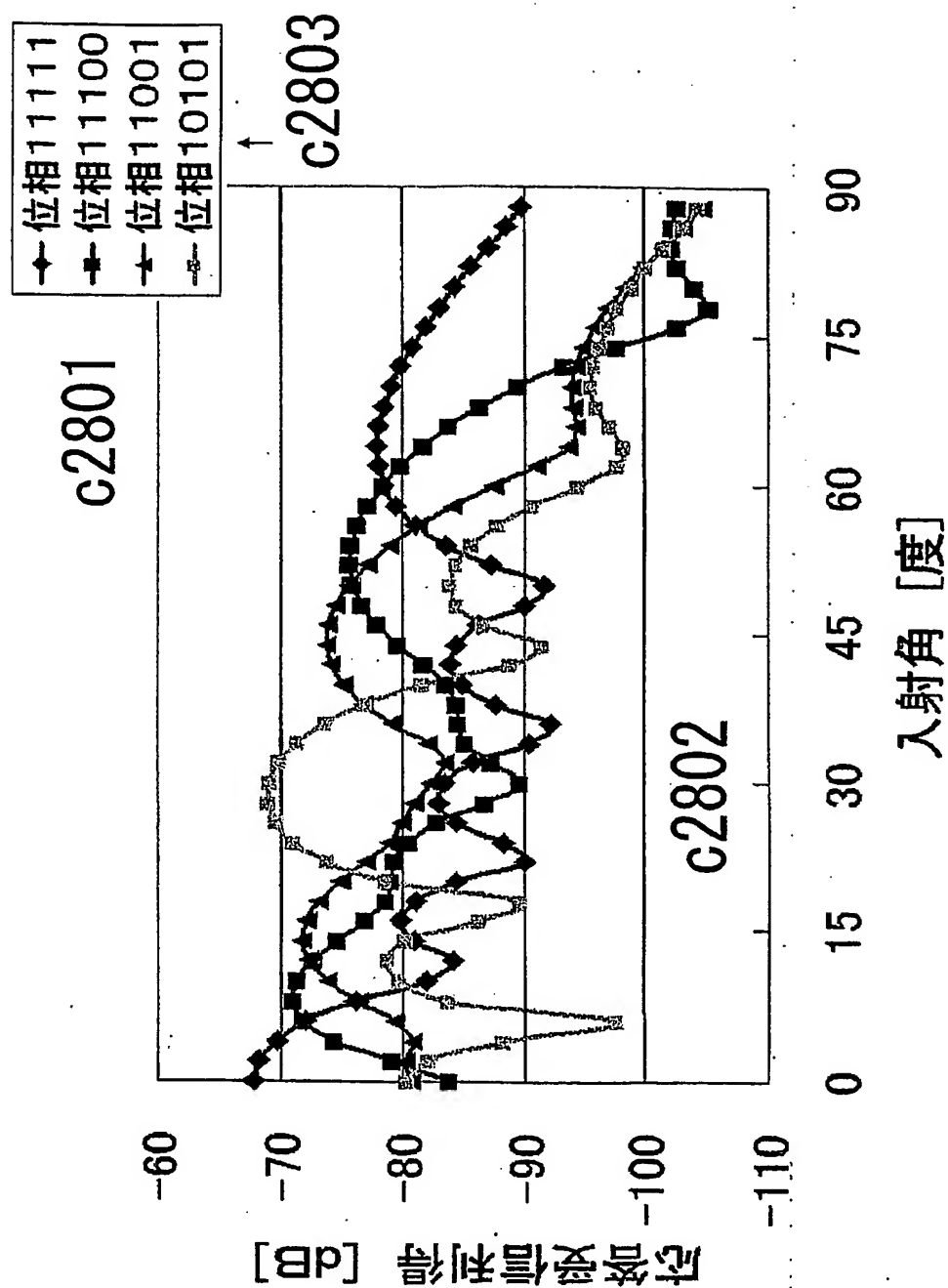
【図 26】



【図 27】



【図 28】



[29]

```

real*4 ep(5), x(5), y(5), z(5), xs(5), ys(5), zs(5)
real*4 al(200), bl(200), cl(201)

ij=1234556
f0=0.05
dlh=15.0/f0      ! cm ] (1)
na=16
write(*,10)
format(' Enter the location of x,y,z (cm) : '$) (2)
read(*,*,end=90) xp,yp,zp

call marray(xp,yp,zp,na,cl) (3)
do i=2,na+1
    verr=ran(ij)
    al(i-1)=cl(i)*(1.0+(verr-0.5)*0.001)-cl(i) ! noise 0.1 % ] (4)
end do
write(*,*) '  $\Delta L$ (cm)', (al(i), i=1,na)
write(*,*)

call mcycle(na,dlh,al) (5)

do j=1,5
    ep(j)=1.0e20
end do

do ix=-30,30
    xp=float(ix)*10.0
    do iy=-30,30
        yp=float(iy)*10.0
        do iz=-30,30
            zp=float(iz)*10.0 ] (6)
        end do
    end do
end do

call marray(xp,yp,zp,na,cl) (7)
do i=2,na+1
    bl(i-1)=cl(i)-cl(i-1)-al(i-1) (8)
end do

call mcycle(na,dlh,bl) (9)
er=0.0
do i=1,na
    er=er+bl(i)**2 (10)
end do
do i=1,5
    if (er .lt. ep(i)) then
        if (i .ne. 5) then
            do j=5,i+1,-1
                ep(j)=ep(j-1)
                x(j)=x(j-1)
                y(j)=y(j-1)
                z(j)=z(j-1)
            end do
        end if
        ep(i)=er
        x(i)=xp
        y(i)=yp
        z(i)=zp
        go to 30 ] (11)
    end if
end do

```

[図30]

```

                                end if
                                end do
                                continue
                            end do
                        end do

do i=1,5
    xs(i)=x(i)
    ys(i)=y(i)
    zs(i)=z(i)
end do

write(*,*) ' RMS error (cm)          x          y          z  (12)
do i=1,5
    write(*,*) sqrt(ep(i)/float(na)), x(i), y(i), z(i)
end do

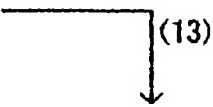
do m=1,5
    x0=xs(m)
    y0=ys(m)
    z0=zs(m)
do ix=-15,15
    xp=float(ix)+x0
do iy=-15,15
    yp=float(iy)+y0
do iz=-15,15
    zp=float(iz)+z0

    call marray(xp, yp, zp, na, cl)
do i=2, na+1
    bl(i-1)=cl(i)-cl(1)-al(i-1)
end do

    call mcycle(na, dlh, bl)
er=0.0
do i=1, na
    er=er+bl(i)**2
end do

do i=1, 5
    if (er .lt. ep(i)) then
        if (i .ne. 5) then
            do j=5, i+1, -1
                ep(j)=ep(j-1)
                x(j)=x(j-1)
                y(j)=y(j-1)
                z(j)=z(j-1)
            end do
        end if
        ep(i)=er
        x(i)=xp
        y(i)=yp
        z(i)=zp
        go to 35
    end if
end do
end do

```



[図31]

```

        continue
      end do
    end do
  end do

  end do
  write(*,*)
  write(*,*) sqrt(ep(1)/float(na)), x(1), y(1), z(1)  (14)

  write(*,*)
  go to 20

  stop
  end

  subroutine marray(xp, yp, zp, na, cl)
    real*4 cl(1)

    cl(1)=sqrt(xp*xp+yp*yp+(zp+50.0)**2)
    do i=2, na+1
      ixx=i/3
      iyy=1-ixx*3
      xm=float(ixx-1)*50.0-10.0
      ym=float(iyy-1)*50.0+10.0
      cl(i)=sqrt((xp-xm)**2+(yp-ym)**2+zp*zp)
    end do

    return
  end

  subroutine mcycle(na, dlh, al)
    real*4 al(1)

    do i=1, na
      continue
      if (al(i) .gt. dlh) then
        al(i)=al(i)-dlh
        if (al(i) .le. dlh) go to 46
        go to 40
      end if
      continue
      if (al(i) .lt. -dlh) then
        al(i)=al(i)+dlh
        if (al(i) .ge. -dlh) go to 46
        go to 45
      end if
      continue
    end do

    return
  end

```

[☒32]

Enter the location of x, y, z (cm) : 152, -203, 56

ΔL (cm)	67.67562	-38.21133	-1.487458	39.09471
-69.24731	-27.88023	16.30007	-91.74537	-46.11990
0.9732714	-102.0754	-54.30361	-5.570741	-98.28325
-51.46763	-3.269386			

RMS error (cm)	x	y	z
0.6834297	150.0000	-200.0000	60.00000
0.8562734	150.0000	-190.0000	50.00000
1.116775	150.0000	-200.0000	50.00000
1.163736	160.0000	-230.0000	70.00000
1.216863	160.0000	-220.0000	60.00000
8.4395386E-02	152.0000	-203.0000	56.00000

Enter the location of x, y, z (cm) : 22, 123, -89

ΔL (cm)	5.506481	57.46710	16.50204	-17.27929
55.74849	14.06553	-20.41722	66.89948	28.19106
-2.332703	89.04320	55.22502	29.83902	119.4193
90.37129	69.39222			

RMS error (cm)	x	y	z
1.445567	20.00000	130.0000	-90.00000
1.754374	20.00000	130.0000	-100.0000
1.951296	20.00000	120.0000	-80.00000
2.345274	20.00000	120.0000	-90.00000
2.709345	20.00000	140.0000	-100.0000
6.2024966E-02	22.00000	123.0000	-89.00000

Enter the location of x, y, z (cm) : 60, 161, 5

ΔL (cm)	-23.45399	32.54938	-13.85323	-57.41031
21.66080	-27.96993	-77.36571	22.85288	-26.38201
-74.96463	36.05470	-9.367880	-51.50449	59.00156
18.86572	-15.62937			

RMS error (cm)	x	y	z
1.358104	60.00000	160.0000	10.00000
1.400364	60.00000	160.0000	0.0000000E+00
1.561480	60.00000	170.0000	0.0000000E+00
1.779230	60.00000	170.0000	10.00000
1.850774	60.00000	150.0000	10.00000
4.4650473E-02	60.00000	161.0000	5.000000

Enter the location of x, y, z (cm) :

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